

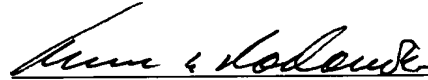
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Attached is a marked-up version of the changes made to the claims by the current Preliminary Amendment.

Entry is believed in order.

Respectfully submitted,



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**Versions with Markings to Claims to Show Changes**

1. (Amended) Robot including at least one linkage device in which pull rods are arranged in a multi-joint system where the joints include three-axle ball and socket joints, wherein [characterized in that] a bearing means [(3)] is fixed so that [it] the bearing means does not rotate in a housing [(2)] in the socket of a joint [(1)], the [where] housing including [(2) includes] a surface [(4)] against which the bearing means [(3)] abuts and [that] the surface being provided [(4) is designed] with friction-increasing means to increase friction between the surface and the bearing means [(5)].

2. (Amended) The robot [Device] according to claim 1, wherein [characterized in that] the bearing means [(3)] comprises an annular bearing means [(3)].

3. (Amended) The robot [Device] according to claim 1, wherein [claims 1-2 characterized in that] the friction-increasing means is structured as to [(5)] penetrate [its material by a permanent deformation of the] bearing means [(3)] effecting a permanent deformation.

4. (Amended) The robot [Device] according to claim 1, wherein [claims 1-3 characterized in that] the friction-increasing means [(5)] are designed in the form] comprise a plurality of grooves [(5)].

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5. (Amended) The robot [Device] according to claim 1, wherein the [claim 1, characterized in that] bearing means [(3)] abuts with the surface [(4)] and is pressed thereagainst to fit tightly.

6. (Amended) The robot [Device] according to claim 4, wherein the [1 characterized in that] grooves [(5)] are oriented primarily parallel with the central axis [(A)] of the bearing means.

7. (Amended) The robot [Device] according to claim 1, wherein [claims 1-6 characterized in that] the bearing means is [made] comprised of a polymer material.

8. (Amended) The robot [Device] according to claim 1, wherein [any of claims 1-7 characterized in that] the robot [is] comprises a delta robot.

Cancel claims 9, 10 and 11.

Add new claims 12, 13, and 14.

--12. A method for eliminating risk of play in a three-axle ball and socket joint in an industrial robot, comprising the steps of providing at least one linkage device for the robot, the device having pull rods arranged in a multi-joint system where the joints each comprise the three-axle ball and socket joint, providing a socket of the joint with a housing to accommodate a bearing means, providing the housing with a

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surface against which the bearing means abuts, fixing the bearing means such that the bearing means does not rotate in the housing, the fixing step being effected by providing the surface with friction-increasing means, and engaging the friction increasing means with the bearing means when the bearing means is positioned in place.

13. The method according to claim 12, comprising the further step of pressing the bearing means to fit tightly in place in the housing of the joint socket.

14. The method according to claim 12, comprising the further step of deforming the material of the bearing means by permanent deformation by the friction-increasing means when the bearing means is placed in position.--

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